

**CLAIMS**

1. **(Previously Presented)** Automatically controlled multi-axis manipulator for a processing tool, comprising at least a first and a second, in particular, hollow component members, wherein said first member, on which said processing tool to be moved by said manipulator is arranged, can be turned relative to said second member, and with a line arrangement that leads to said processing tool on or through the component members and is fixed on a part of said processing tool, wherein said part of said processing tool on which said line arrangement is fixed is supported in a rotatable fashion relative to said first component member.
2. **(Previously Presented)** The manipulator according to Claim 1, wherein said part of said processing tool on which said line arrangement is fixed is rotatably supported in an outer housing that is rigidly connected to said first component member.
3. **(Previously Presented)** The manipulator according to Claim 1, wherein said line arrangement leading to processing tool contains supply hoses for at least one of liquid, gaseous media, and signal lines.
4. **(Previously Presented)** The manipulator according to Claim 1, comprising a flexible shaft for absorbing torque leads through said component members parallel to said line arrangement and fixed on said rotatably supported part of said processing tool.
5. **(Previously Presented)** The manipulator according to Claim 2, wherein said component members form a wrist joint of a robot.

6. (Previously Presented) The manipulator according to Claim 5, wherein said processing tool consists of an atomizer or another application device that is moved by said robot, and said interior part of said processing tool which is connected to said line arrangement is rotatably supported in said outer housing of said atomizer or the like which is rigidly connected to said wrist joint of said robot.

7. (Previously Presented) The manipulator according to Claim 6, comprising an annular ring for a medium to be conveyed through the processing tool is formed between the outer side of said interior part of said processing tool which is connected to said line arrangement and its outer housing that is rigidly connected to the first component member, wherein said ring is limited by sliding seals that are seated between the inner side of said outer housing and the outer side of said interior part and adjoin said housing and said interior part.

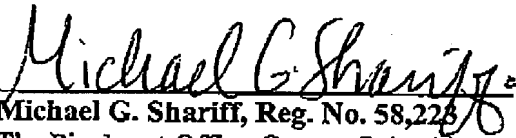
8. (Previously Presented) The manipulator according to Claim 7, comprising a sealed rotary leadthrough provided within said processing tool for at least one line for a medium to be conveyed outwardly through said processing tool, wherein said medium is conveyed through at least one of a central channel that extends along a central axis of said processing tool and through a ring channel.

9. (Previously Presented) The manipulator according to Claim 8, comprising at least one additional rotary leadthrough provided for at least one line that terminates in the processing tool.

10. (Previously Presented) The manipulator according to Claim 9, wherein said processing tool is supported on a mechanical interface of said wrist joint of a robot, and is rotatable in its entirety relative to this interface.

Respectfully submitted,

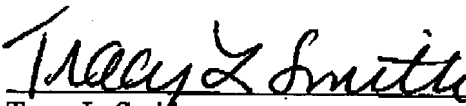
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**CERTIFICATE OF FACSIMILE TRANSMISSION**

I hereby certify that the attached **Response to Restriction Requirement** is being facsimile transmitted to the Commissioner for Patents and Trademarks, Alexandria, Virginia, to the attention of **Examiner Davis D. Hwu** from **Group: 3752** to facsimile number **(571) 273-8300** on **October 4, 2007**.

  
Tracy L. Smith